## ABSTRACT

In a motor control device according to the invention, upon velocity control of a motor, a superimposed signal generating unit 9 outputs a superimposed signal idh of a repetitive waveform, such as a triangular wave or a sine wave. A d-axis current command generating unit 10 adds the superimposed signal idh generated by the superimposed signal generating unit 9d to a d-axis current command $idc^*0$ and outputs a d-axis current command $idc^*$. An axial misalignment detecting unit 11 (11a, 11b, 11c, and 11d) receives the d-axis current command $idc^*$ and a q-axis current command $iqc^*$ and outputs an axial misalignment angle estimation value $\Delta\theta\hat{}$. An axial misalignment correction unit 12 receives the axial misalignment angle estimation value $\Delta\theta\hat{}$ and an actual detected position $\theta m$ and outputs a position after correction $\theta m'$. Therefore, detection and correction can be performed in real time through calculation at a given timing during a normal operation.